IN THE SPECIFICATION:

Please amend the paragraph beginning at line 14 of page 46 as follows:

d2

This pneumatic control means is cited as a preferred embodiment for the purpose of example, but the essential function of control means 71 is more generally as depicted in the block diagram of Figure 12, in which a distance or level signal in some form 150, is first preferably passed through first low pass filter means 151, then through summer 152 which compares the filtered signal with a reference level 153, followed by a gain 154 with deadband ~~154~~. Gain 154 may, but need not, be substantially linear outside the region of the deadband ~~154~~. The output from gain 154 is preferably passed through second low-pass filter means 155, and then to a throttling transducer 156.

Please amend the paragraph beginning at line 25 of page 46 as follows:

d3

The functions of these elements of control means 71 are as follows. First low pass filter 151 converts a position signal 150, including a very low frequency bias upon which is superimposed a relatively high frequency vibration component of significant amplitude, into a slowly varying signal representing average position along with a small high frequency ripple component. Summer 152 subtracts the reference 153 to provide an output error signal generally near zero in amplitude except for the small high frequency ripple. Gain 154 with deadband ~~154~~ then generally passes only vibrational peaks, either positive or negative, indicative of a shift in the average input signal from the reference level.

Please amend the paragraph beginning at line 10 of page 48 as follows:

d4

If gain 154 with the deadband ~~152~~ were not present, then the signal reaching throttling transducer means 156 would include both an average error signal and a high frequency component reflecting the vibration being isolated, which could be substantial, and

d4 cont

throttling transducer means 156 would be attempting to respond to an alternating positive and negative signal. The alternating error signal would lead to a drain on stored energy, which may be severely limited, as well as to constant vibrational chattering of the mechanisms being controlled by the control means 71, even if the average of that signal was zero and no net motion was required.

Please amend the paragraph beginning at line 21 of page 48 as follows:

d5

In the most optimal configuration with respect to position control, the width of the deadband in gain ~~152~~ 154 is made a function of the vibration being isolated, being always just wider than the peak-to-peak amplitude of vibration. In this manner, the control means 71 will respond to any shift in the very low frequency bias of the input position signal 150 so that the error in position is always very near zero. However, this is a degree of sophistication which, it is believed, will be required only in a minority of applications. More commonly, a fixed deadband with width greater than the peak-to-peak amplitude of the most severe expected vibration will be sufficient.